

ACQUIRING AND PROCESSING METHOD FOR IMAGE

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Abstract of JP 9072717 (A)

PROBLEM TO BE SOLVED: To make it possible to apply to the tracking operation of a robot by conducting the image acquiring and processing utilizing a visual sensor by a simple system.

SOLUTION: A conveyor 1 for conveying a work to be supplied from a work supply source 100 is driven by a driver 2, and its moving amount is detected by a pulse encoder 3. A visual sensor VS having an image processor 20 and a camera 30 so repeatedly acquires the image corresponding to a visual field 31 at an interval as not to generate an imaging leakage area or leak of the imaging of the work by utilizing the detected output of the encoder 3, and detects the deviation from the reference position (a, b, c, d) of the work W. The robot control unit 10 of a robot controller RC starts the tracking operation of the work coming from the initial position P0 to the vicinity of the tracking starting line 60 of the robot RB. The tracking operation with the position correction is conducted between ranges 60 to 70 to catch up the work W, thereby completing the predetermined operation.

